

LIST OF CURRENT CLAIMS

1. (Amended) An articulated industrial robot, comprising:
 - a robot arm including a plurality of arm components swingably connected to one another by connection shafts; and
 - a base to which the robot arm is connected,
 - wherein the robot arm includes arm actuation means for swinging the arm components,
 - the arm components ~~includes~~ include a first arm component at a tip side of the robot arm, the first arm component having a tip-side end and a wrist at ~~[[it]]~~ the tip-side end,
 - the arm components includes a second arm component, the second arm component being positioned between the first arm component and the base ~~which is closer to the base than the first arm component is~~, the second arm component being divided at an axially intermediate position into a base-side part and a tip-side part, and the second arm component having rotation means for rotating the tip-side part around the arm axis relative to the base-side part,
 - the rotation means includes a drive shaft extending in ~~[[the]]~~ an arm axis direction and having a thread groove in ~~[[its]]~~ an outer surface, the arm axis extends in a longitudinal direction of the second arm component, a moving device for axially moving the drive shaft, and a threaded member meshed with the thread groove of the drive shaft, and
 - the moving device is fixed to one of the base-side part and the tip-side part, while the threaded member is fixed to the other, and wherein:
 - the base-side part and the tip-side part of the second arm component are hollow; and
 - the moving device is contained in one of the hollow base-side part and the tip-side part, while the threaded member is contained in the other.

2. (Cancelled)

3. (Amended) The industrial robot of claim 1 ~~or 2~~, wherein the moving device includes a nut meshed with the thread groove of the drive shaft, a motor for rotating

the nut around the drive shaft, and a speed reduction mechanism for reducing a rotation speed of the output shaft of the motor to transmit a torque of the motor to the nut.

4. (Amended) The industrial robot of ~~any one of claims 1 to 3~~ of claim 1, wherein the first arm component includes wrist actuation means for reciprocating the wrist in the arm axis direction.

5. (Cancelled)

6. (New) The industrial robot of claim 3, wherein the first arm component includes wrist actuation means for reciprocating the wrist in the arm axis direction.

7. (New) The industrial robot of claim 1, wherein the first arm component is directly connected to the second arm component.

8. (New) The industrial robot of claim 1, wherein the first arm component is connected to the second arm component with another arm component interposed therebetween.

9. (New) The industrial robot of claim 1, wherein the second arm component is directly connected to the base.

10. (New) The industrial robot of claim 1, wherein the second arm component is connected to the base with another arm component interposed therebetween.